

**IN THE CLAIMS:**

Please amend claim 1 as follows.

1. (Currently Amended) A leg type mobile robot comprising:

a body;

legs each connected to the body via a first joint; and

feet, each connected to an end part of the leg via a second joint, wherein each foot includes

at least one foot portion, which has ~~a~~at least two ground area~~areas~~ to be grounded on a floor surface at a bottom thereof, and

a floor reaction force detector configured to detect a floor reaction force acting from ~~a~~the floor surface through at least one of the two ground areas the foot portion, and wherein

in a ~~plane footprint~~ view from overhead, when the robot is in a standing-still state,

a center of the second joint is offset against a position,

the position is ~~the position in the ground area and has an equal distance to each remotest point of the ground area~~of equal distance to a point on each ground area, wherein the point on each ground area is most remote on the ground area from the position, and

a center of the floor reaction force detector is closer to the position than to the center of the second joint.

2. (Previously Presented) A leg type mobile robot according to claim 1, wherein the center of the floor reaction force detector is offset to a rear direction with respect to the position.

3. (Previously Presented) A leg type mobile robot according to claim 2, wherein the center of the floor reaction force detector is positioned on a line segment connecting the position and the center of the second joint.

4. (Previously Presented) A leg type mobile robot according to claim 1, wherein the center of the floor reaction force detector is offset to a rear direction in a center side of the leg type mobile robot with respect to the position.

5. (Previously Presented) A leg type mobile robot according to claim 4, wherein the center of the floor reaction force detector is located on the perpendicular taken down from the center of the second joint to the line segment extended from the position to a rear direction.

6. (Previously Presented) A leg type mobile robot according to claim 4, wherein the center of the floor reaction force detector is located on the perpendicular taken down from the center of the second joint to the line segment extended from the position to a center of the leg type mobile robot.

7. (Previously Presented) A leg type mobile robot according to claim 4, wherein the center of the floor reaction force detector is positioned on a line segment connecting the position and the center of the second joint.